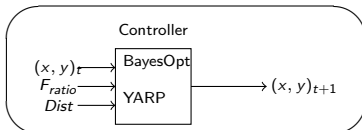
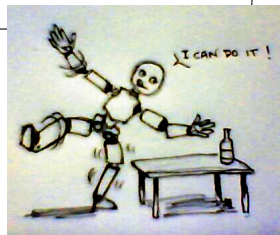
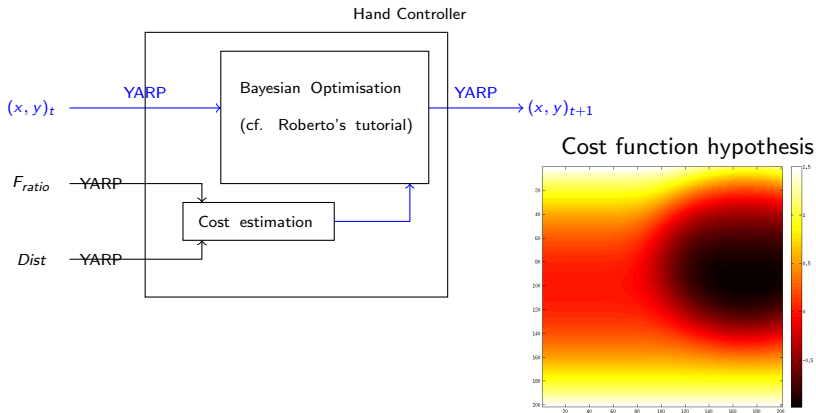


Learning to reach an object while staying balanced

What I did :

- Tried to answer these questions :
 - What to learn ? Policy, model ?
 - How to evaluate balance in a multicontact situation ?
- Took some force measurement (to estimate the ratio criterion) on the robot
- Developed a module using BayesOpt and Yarp (still in progress)
- Enjoyed the school !





- ratio $\frac{F_T}{F_N}$ criterion : should be reevaluated.
- "CoM over contacts triangle" criterion : should be tested.
- Find a clever way to make BayesOpt use informations from sensors over time (the progress stuff).